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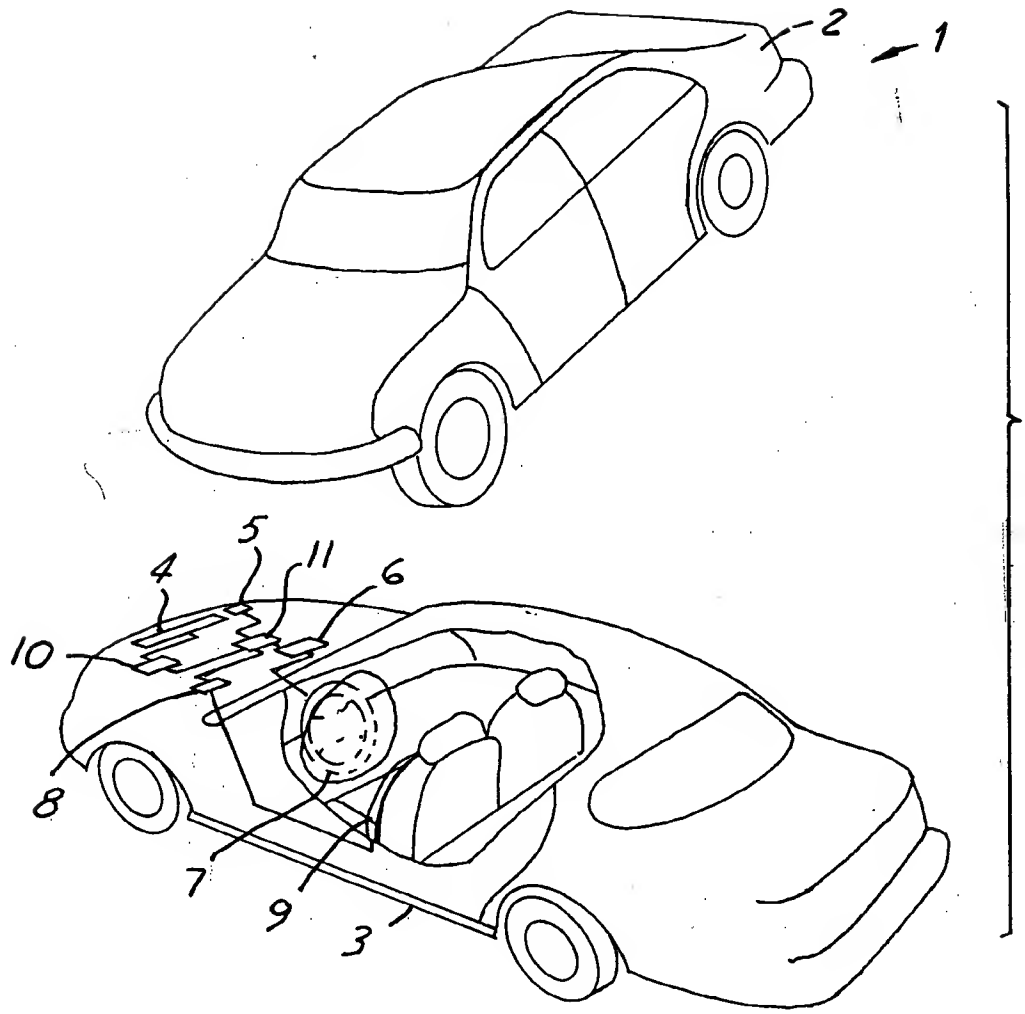

FIG. 1

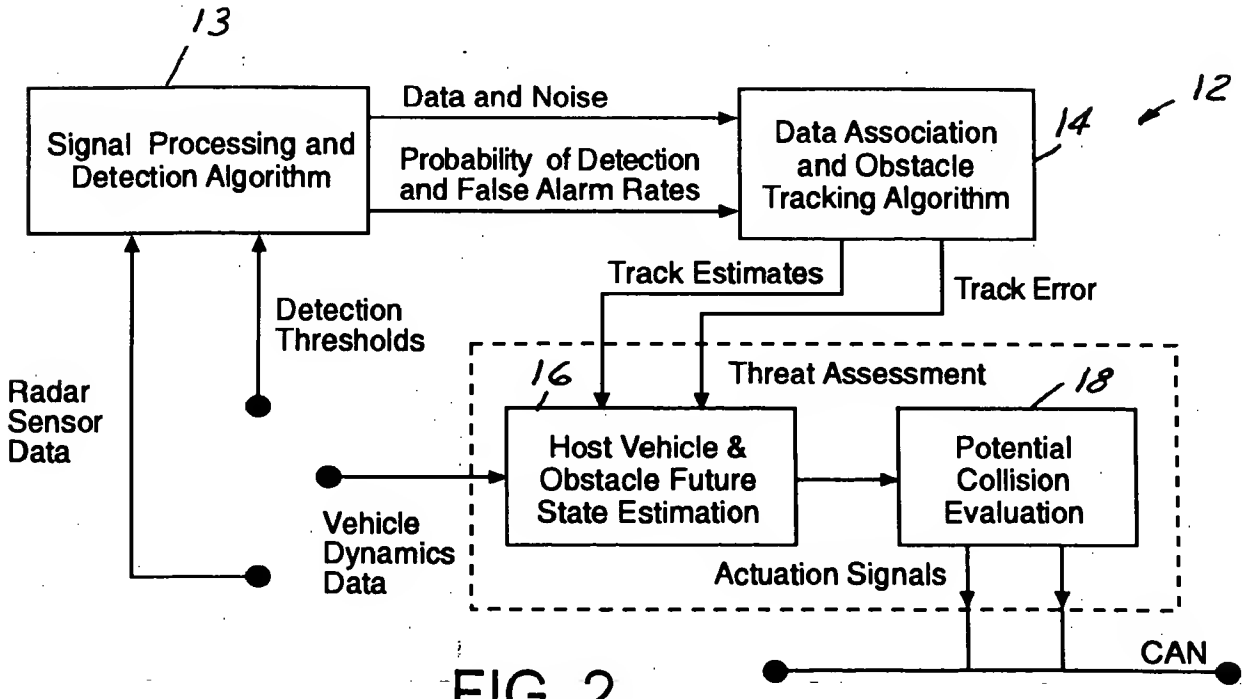

FIG. 2

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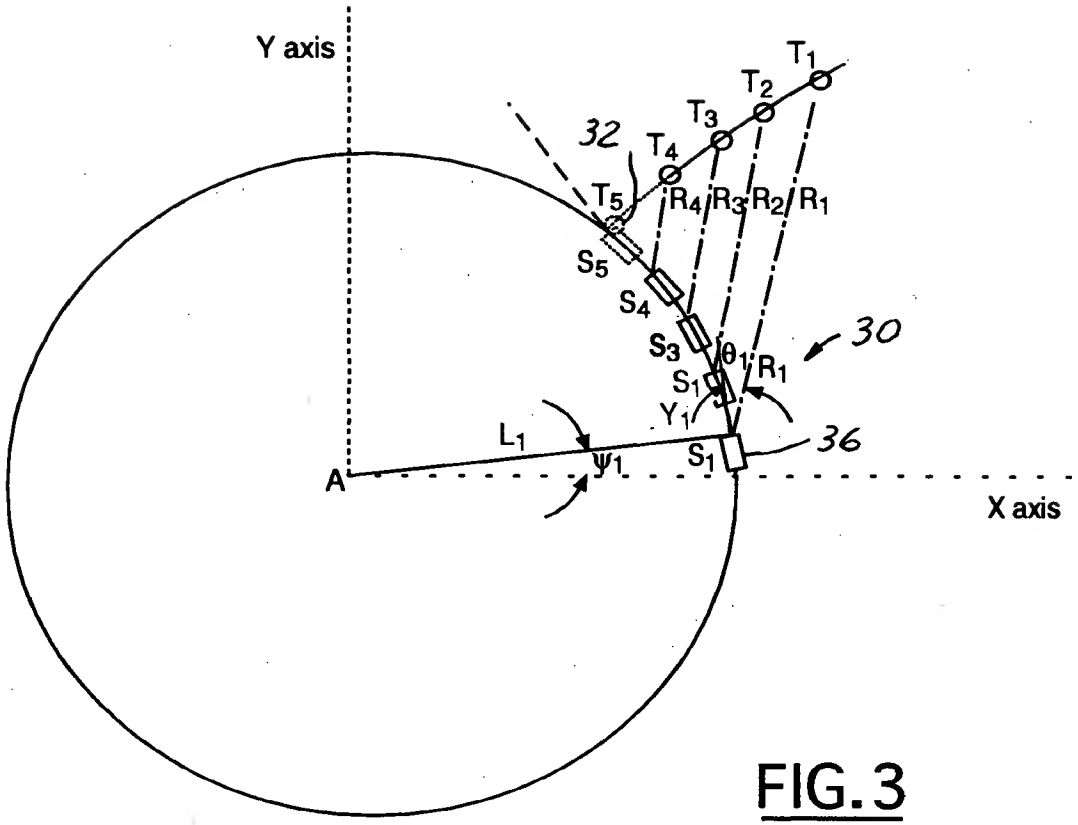

FIG. 3

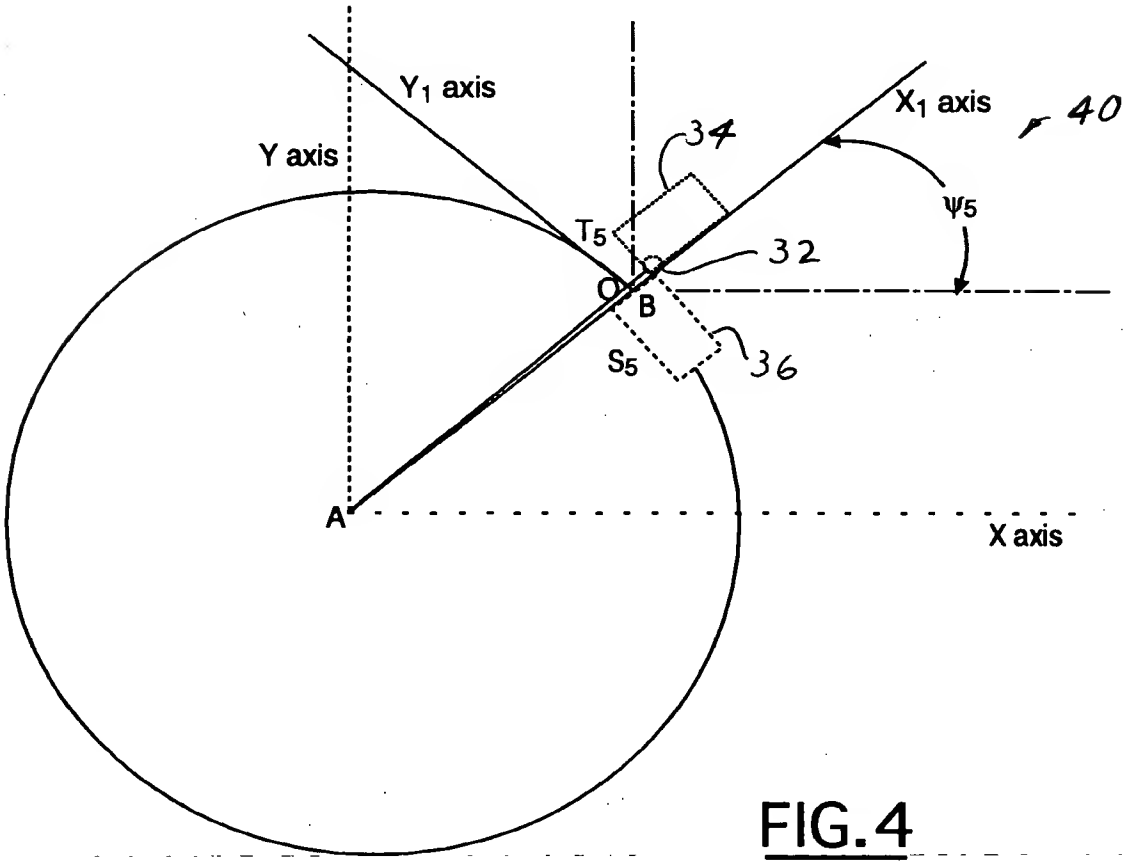

FIG. 4

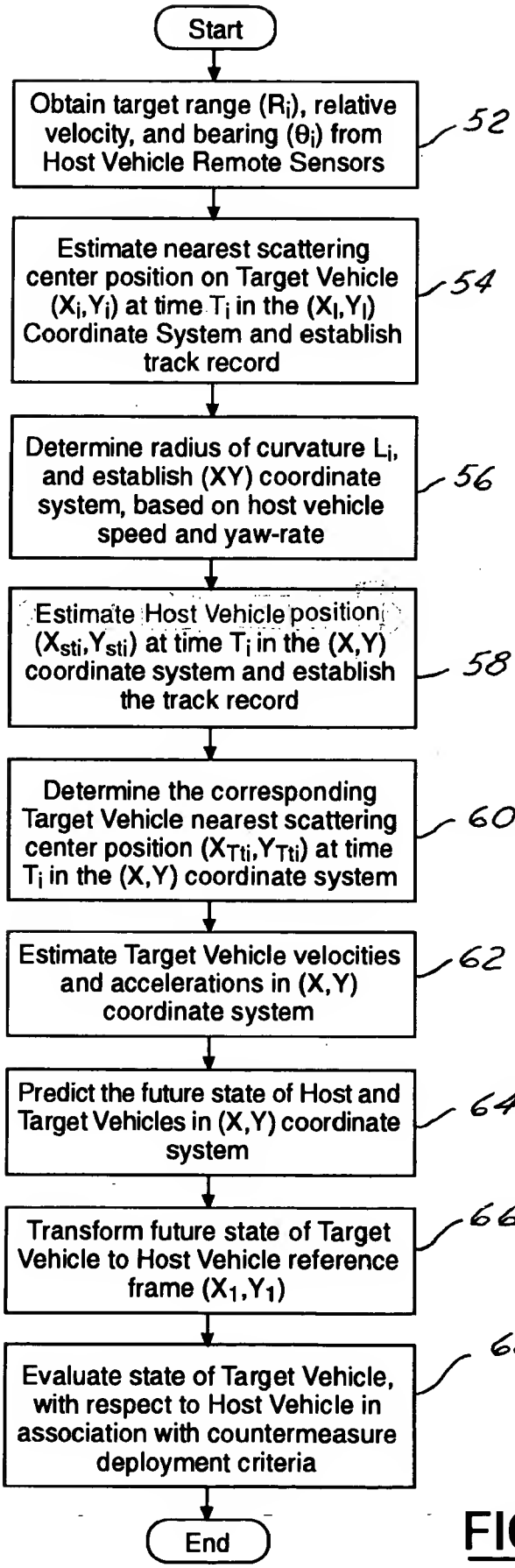
Start
Obtain target range (R_i), relative velocity, and bearing (θ_i) from Host Vehicle Remote Sensors
52
Estimate nearest scattering center position on Target Vehicle (X_i,Y_i) at time T_i in the (X_I,Y_I) Coordinate System and establish track record
54
Determine radius of curvature L_i, and establish (XY) coordinate system, based on host vehicle speed and yaw-rate
56
Estimate Host Vehicle position (X_{sti},Y_{sti}) at time T_i in the (X,Y) coordinate system and establish the track record
58
Determine the corresponding Target Vehicle nearest scattering center position (X_{Tti},Y_{Tti}) at time T_i in the (X,Y) coordinate system
60
Estimate Target Vehicle velocities and accelerations in (X,Y) coordinate system
62
Predict the future state of Host and Target Vehicles in (X,Y) coordinate system
64
Transform future state of Target Vehicle to Host Vehicle reference frame (X_1,Y_1)
66
Evaluate state of Target Vehicle, with respect to Host Vehicle in association with countermeasure deployment criteria
68
End

FIG. 5